

## Figures

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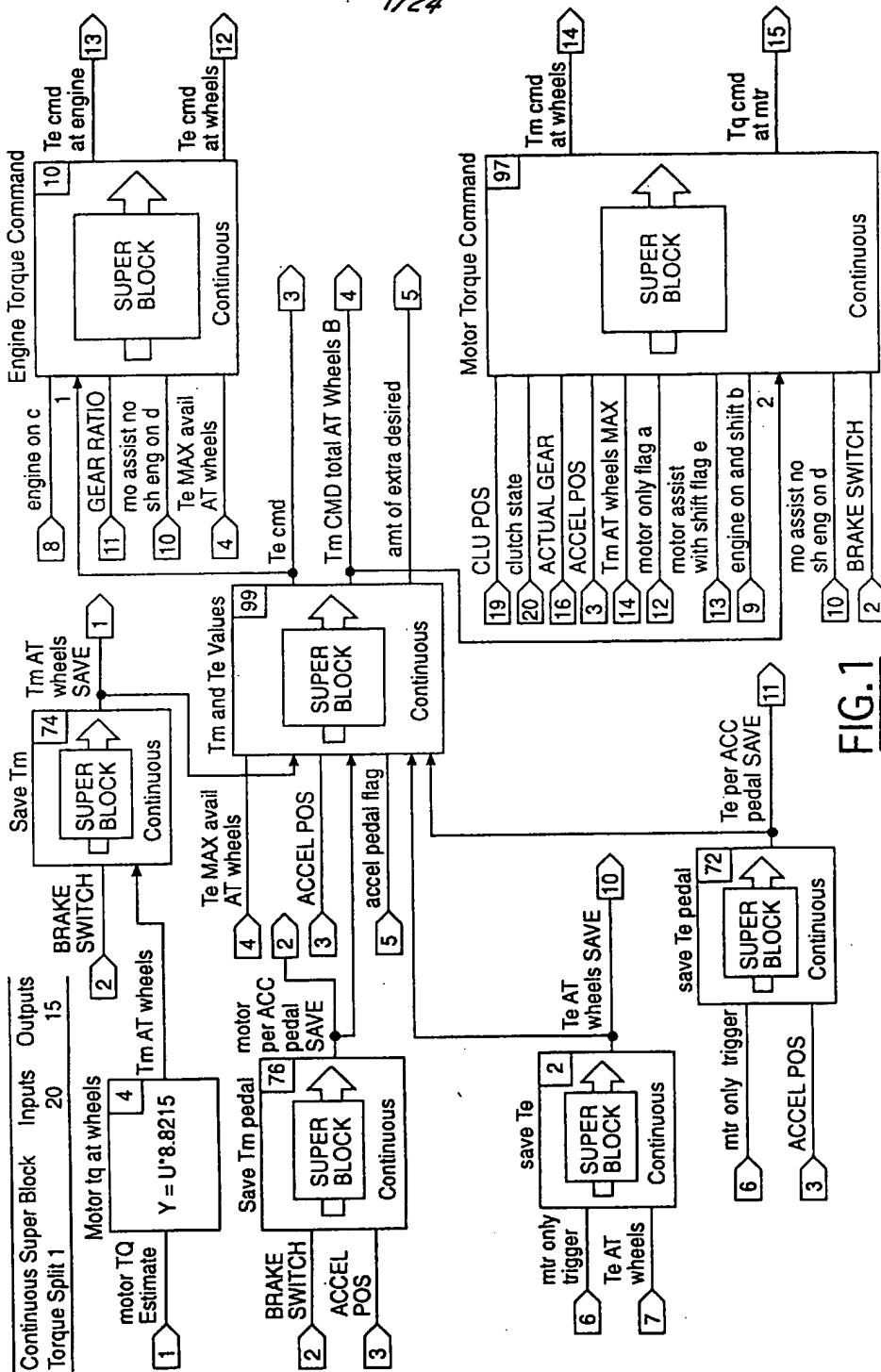
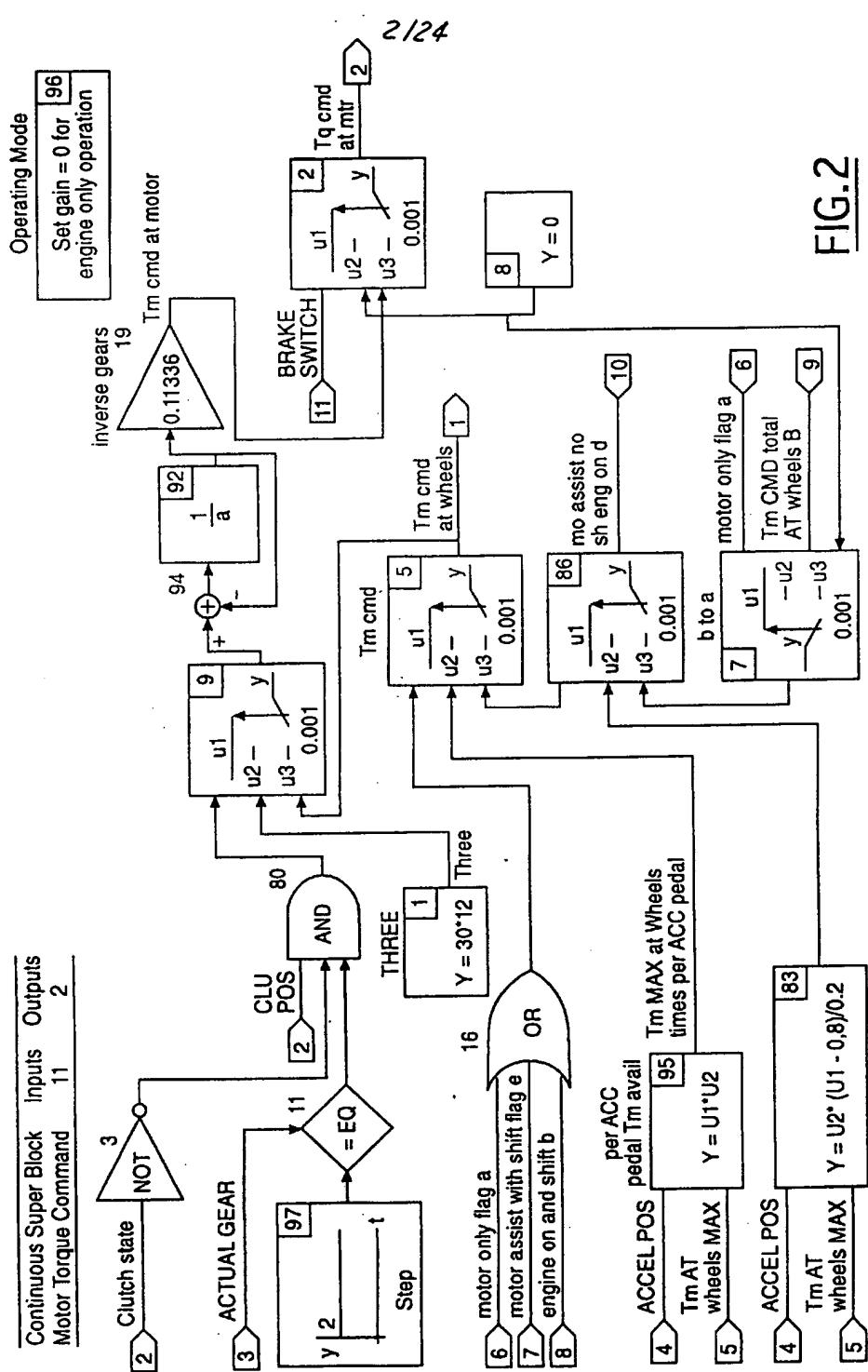


FIG. 1



**FIG.2**

Continuous Super Block  
save Tm Pedal

## EVENT DRIVEN BUFFER

Actual value is:  $((1 - \exp(-\lambda * t)) / \lambda) * error$   
 Current value for  $\lambda * t$  is -10  
 Event driven reset integration may also be employed  
 Euler integration is sufficient for the discrete form.  
 (example shown below is for update rate = .01 sec)

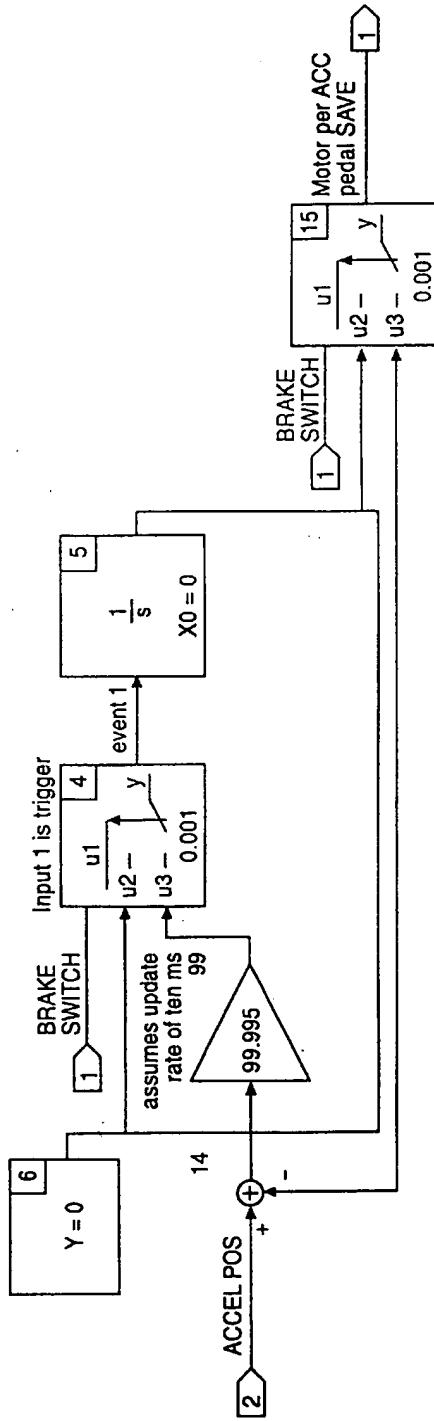
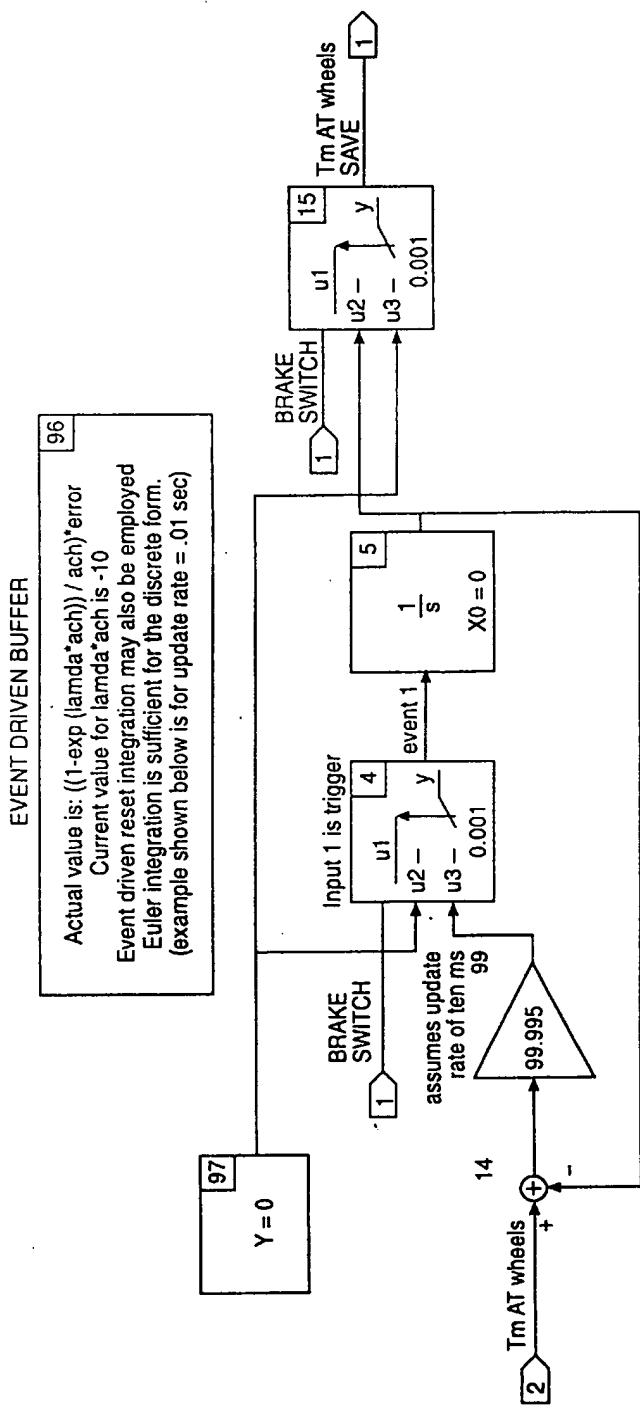
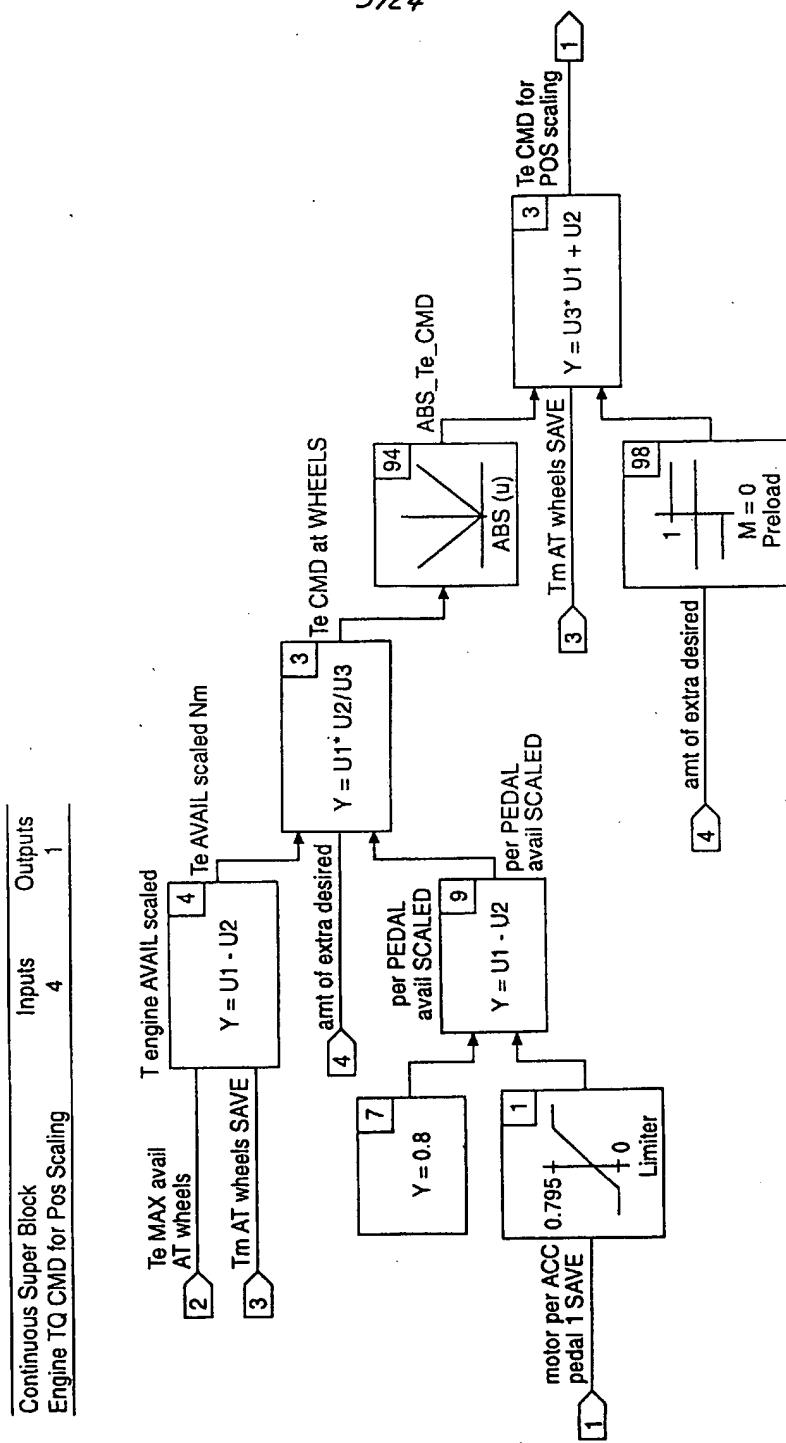
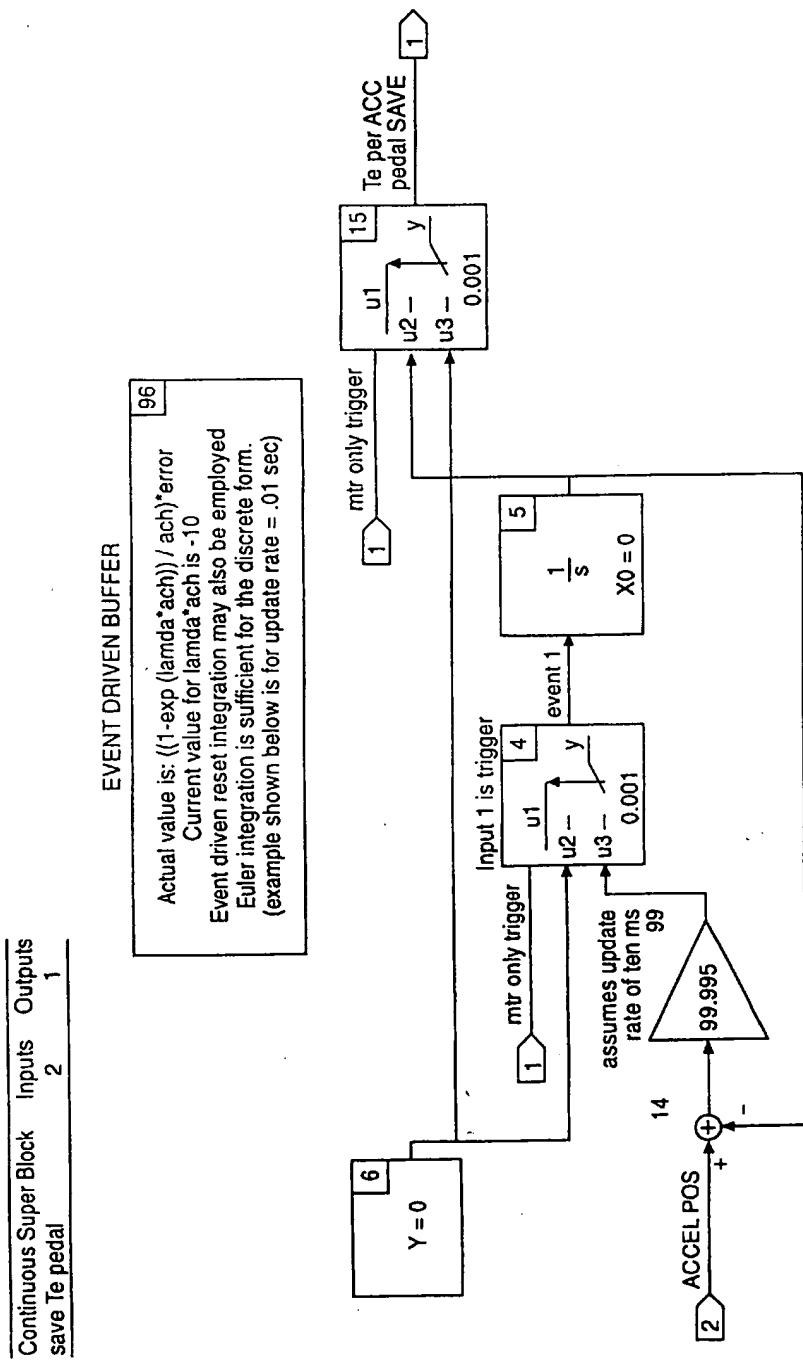


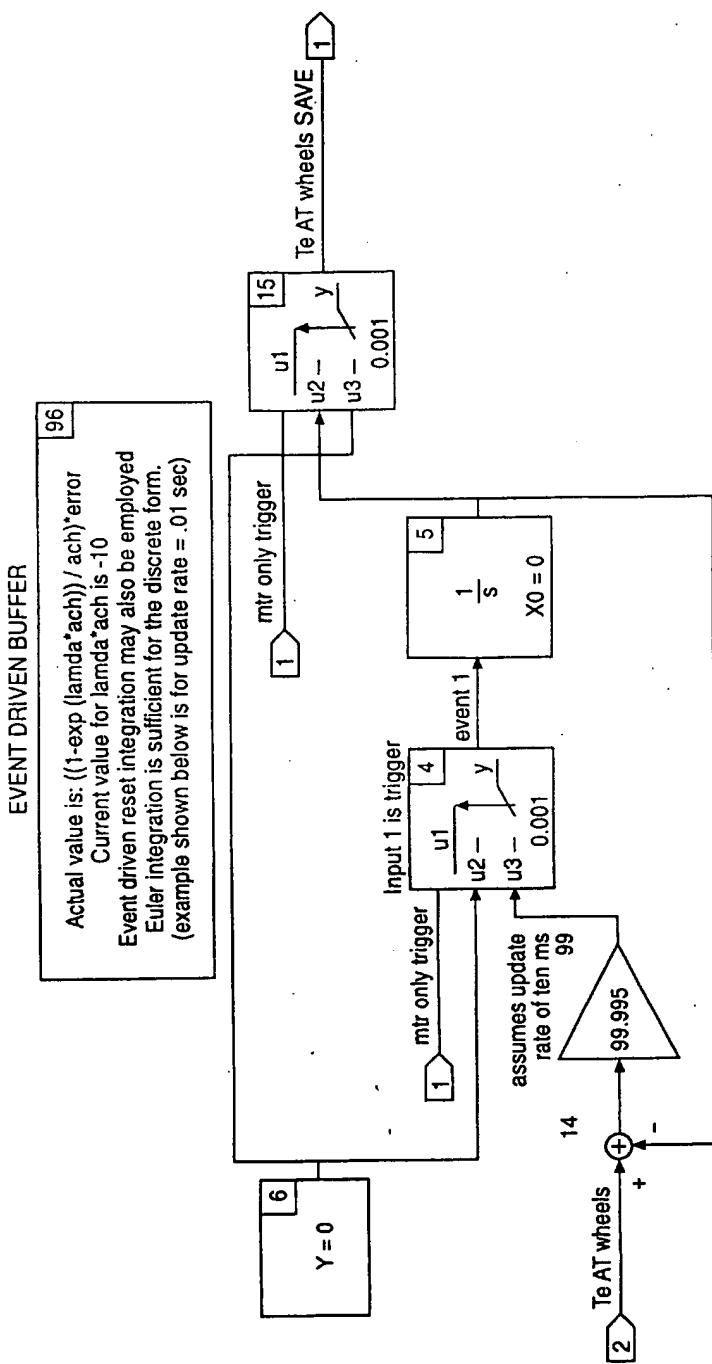
FIG.3

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FIG. 4

FIG. 5

**FIG.6**

**FIG.7**

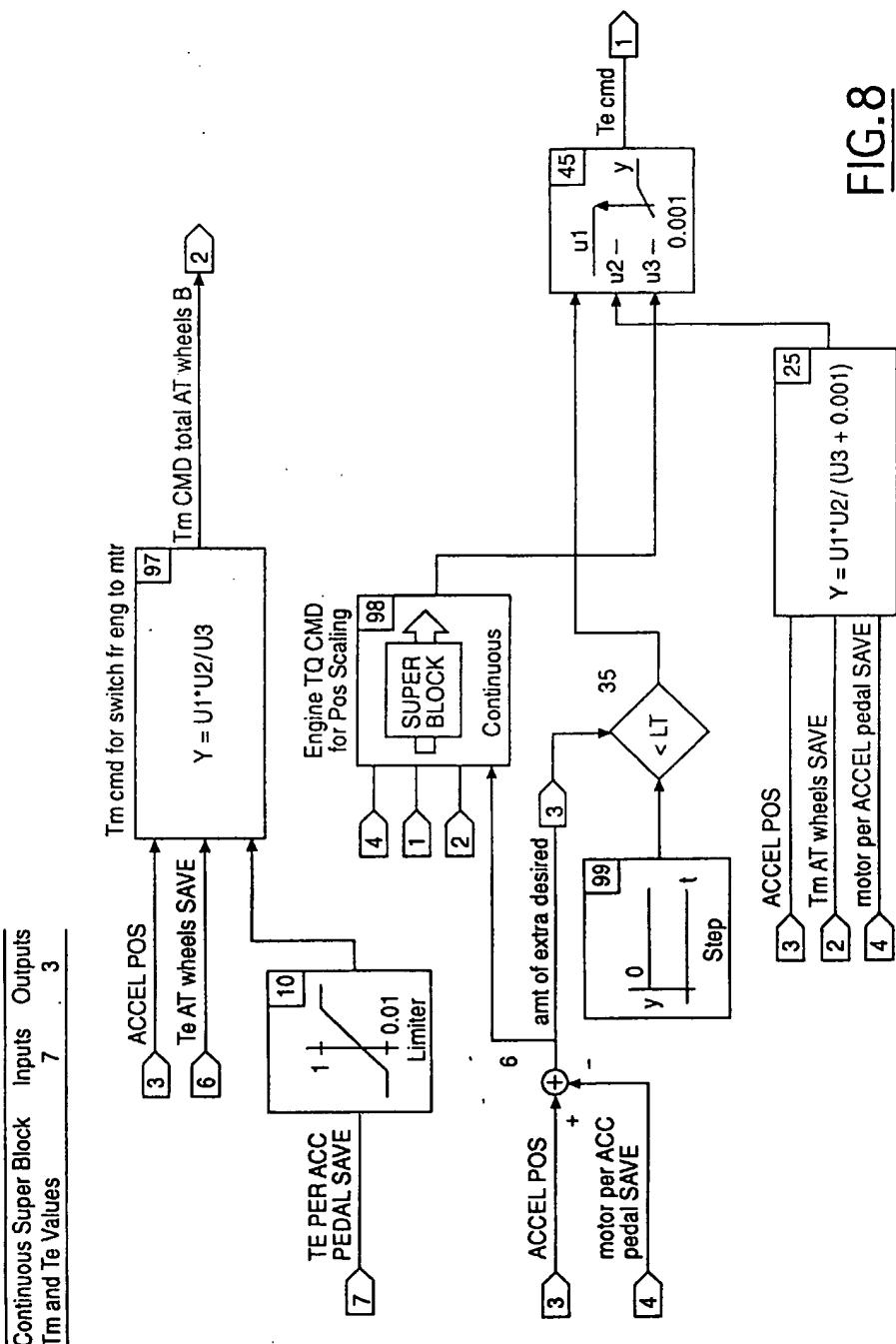


FIG. 8

Continuous Super Block	Inputs	Outputs
Engine Tq Command	5	2

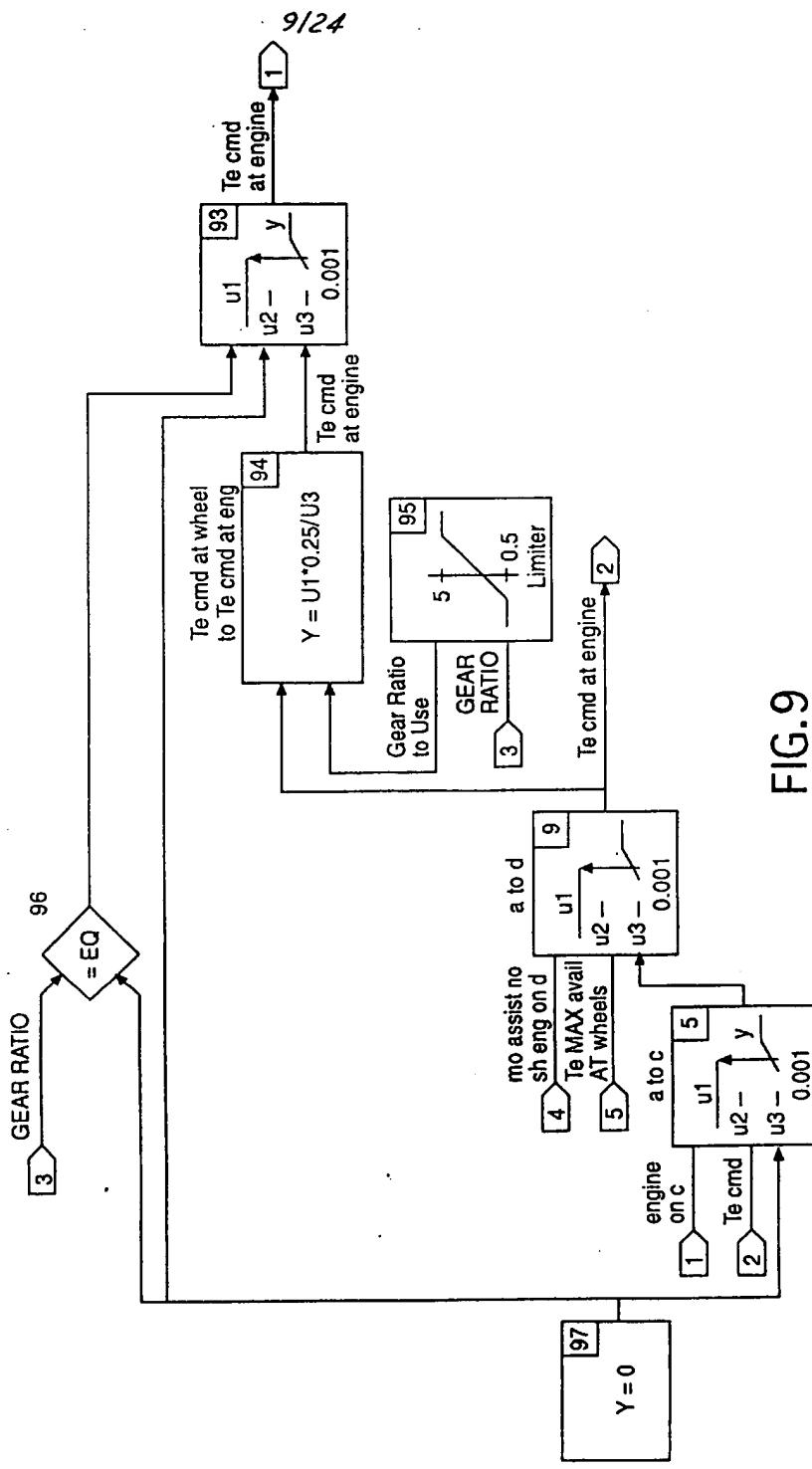


FIG. 9

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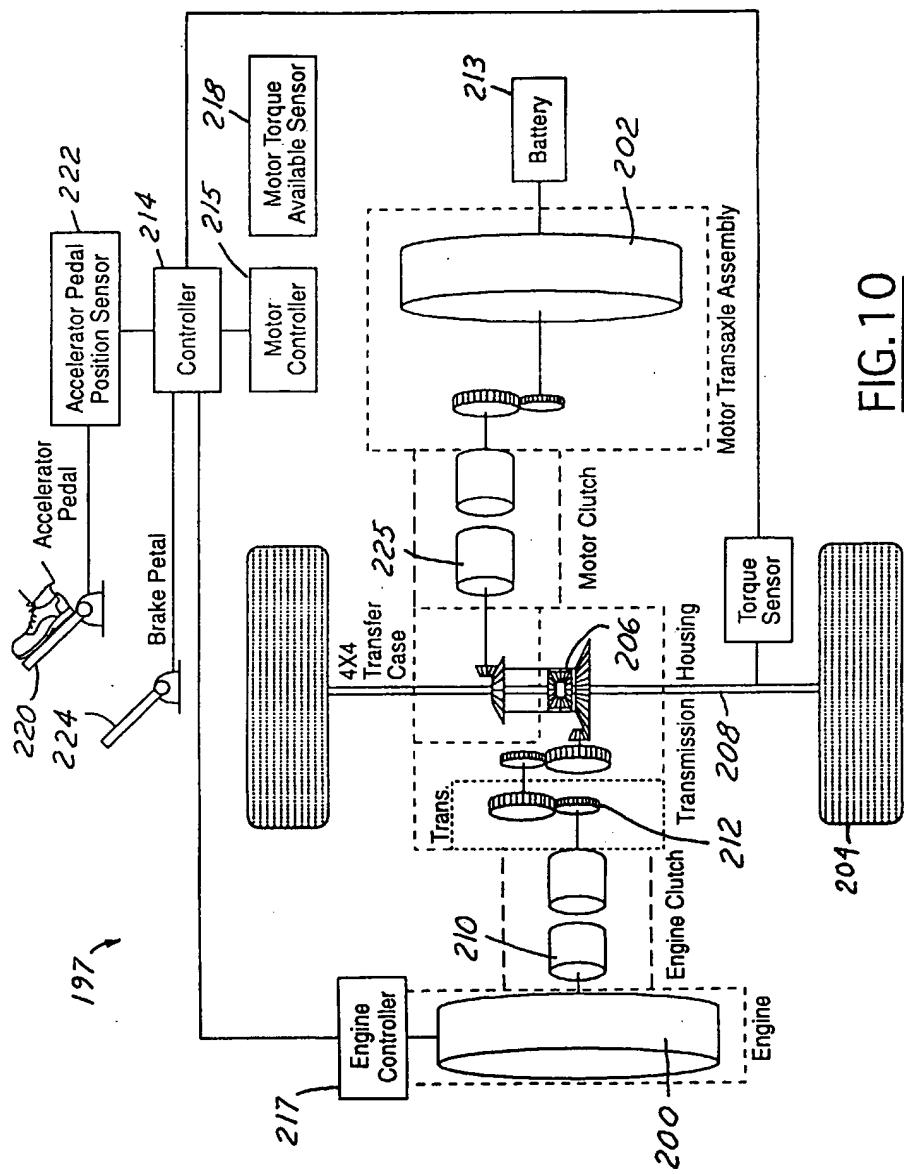
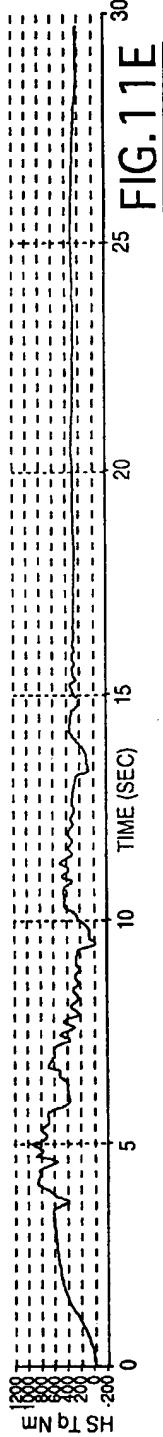
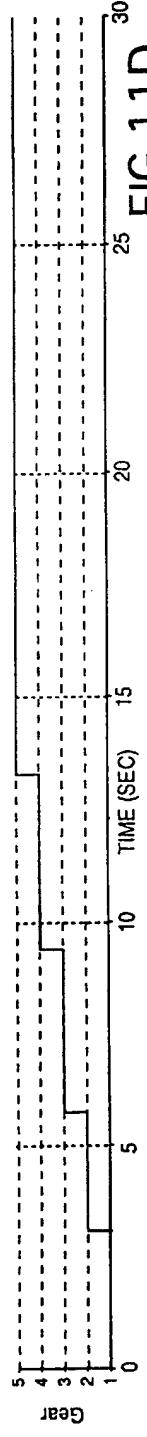
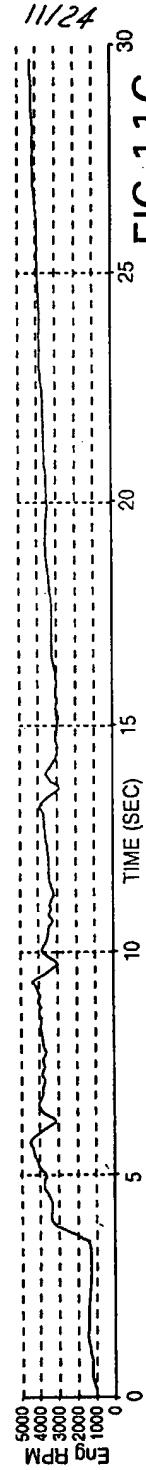
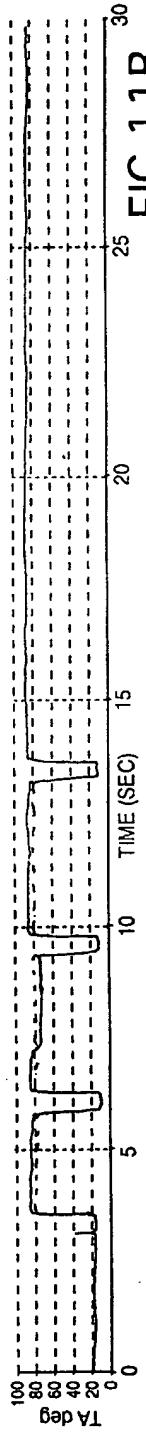
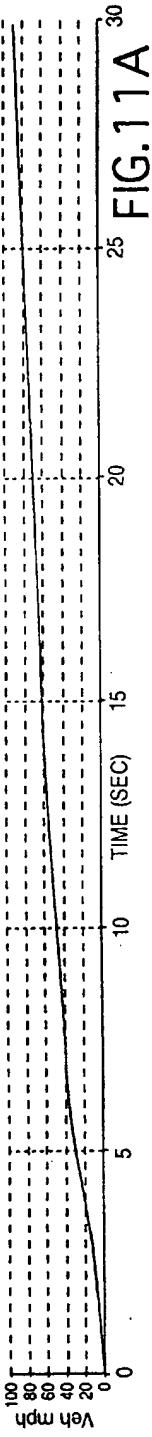
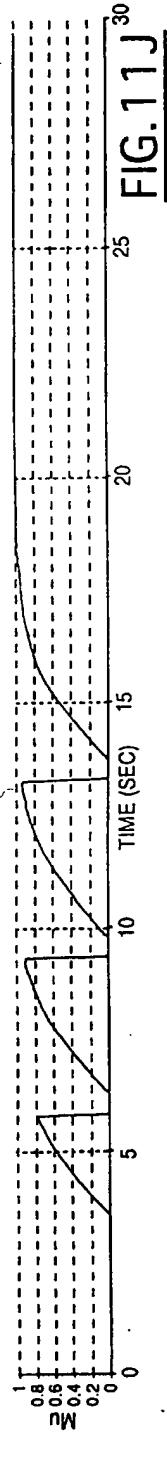
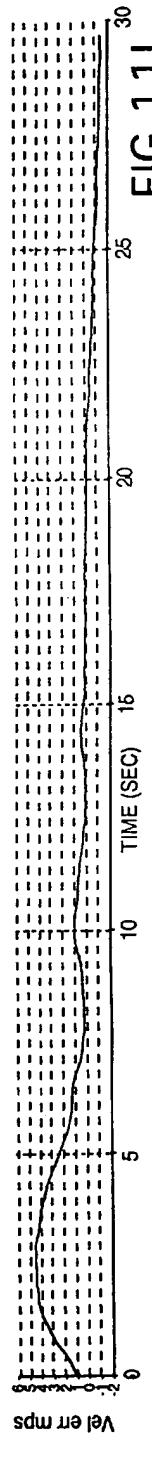
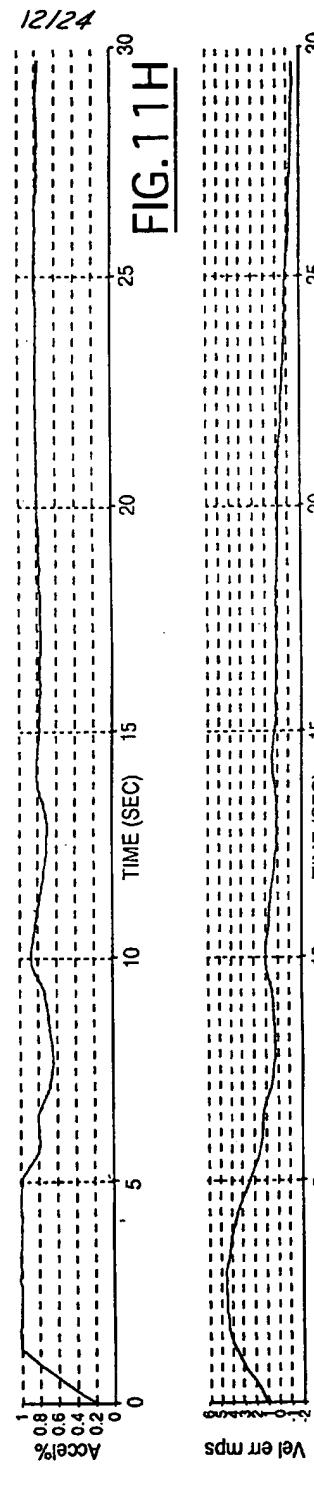
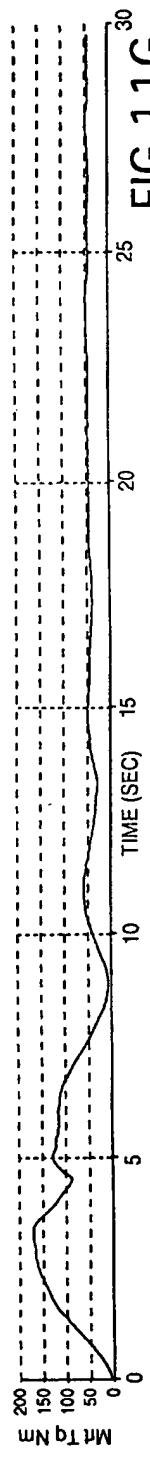
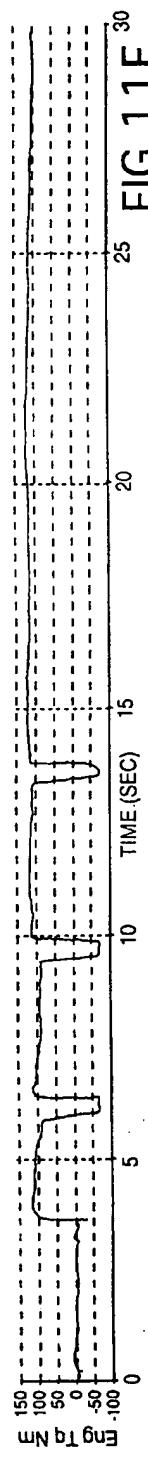


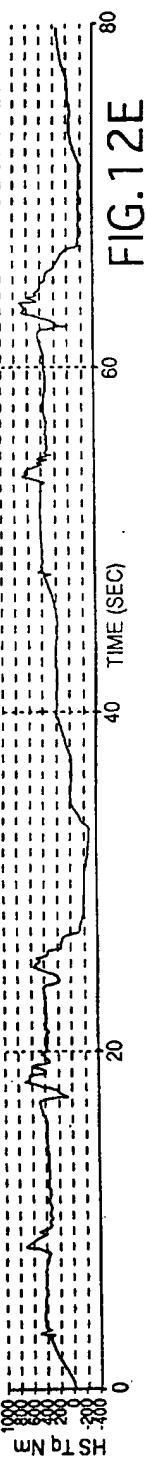
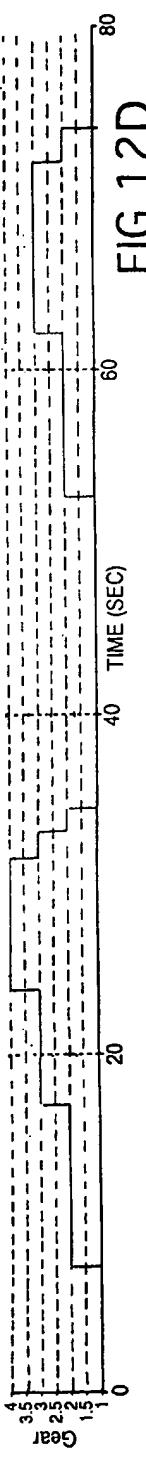
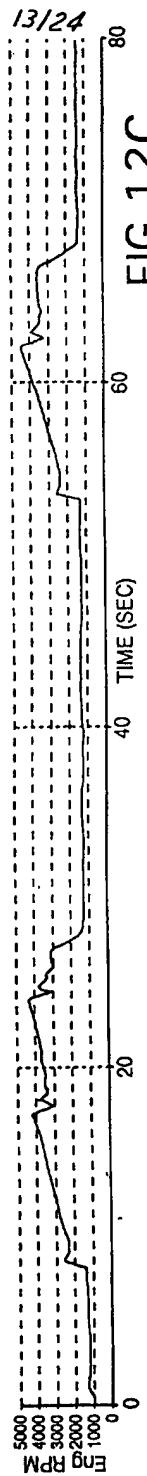
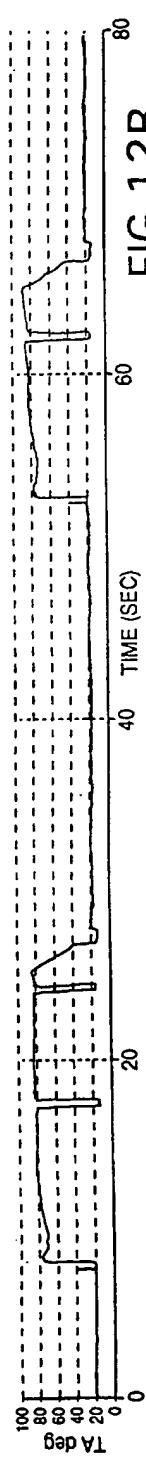
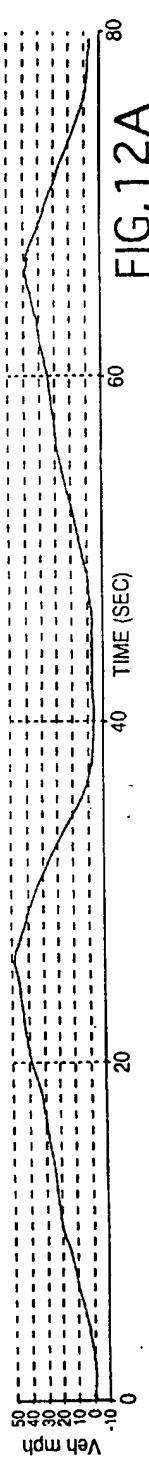
FIG. 10



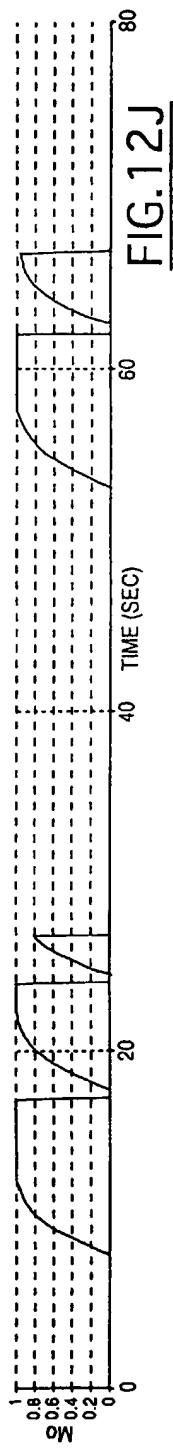
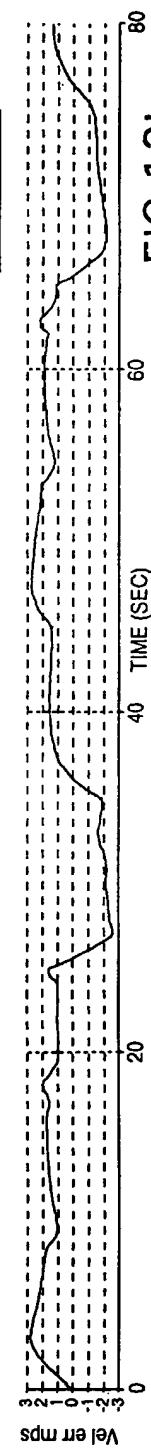
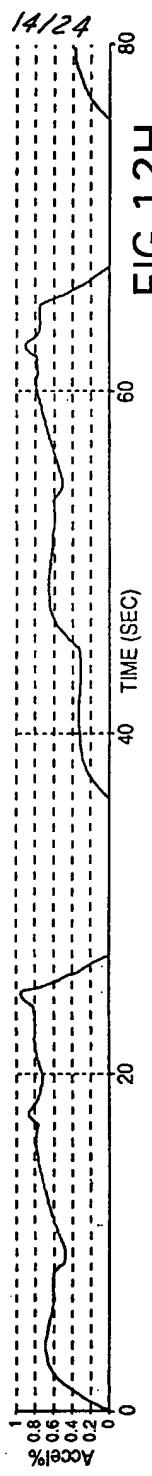
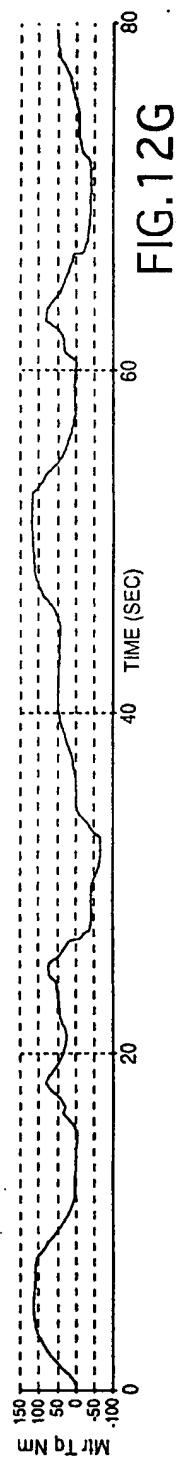
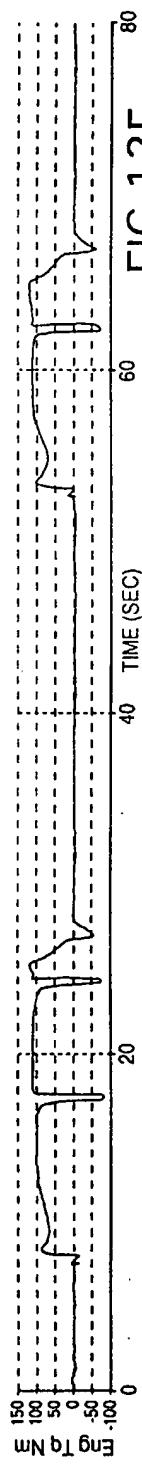
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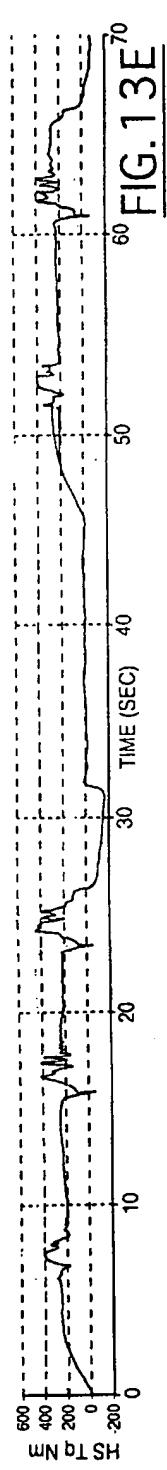
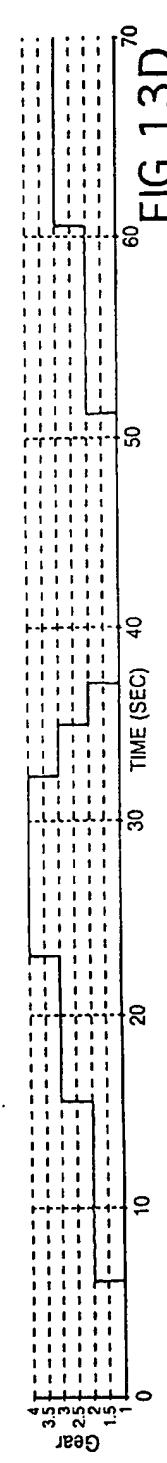
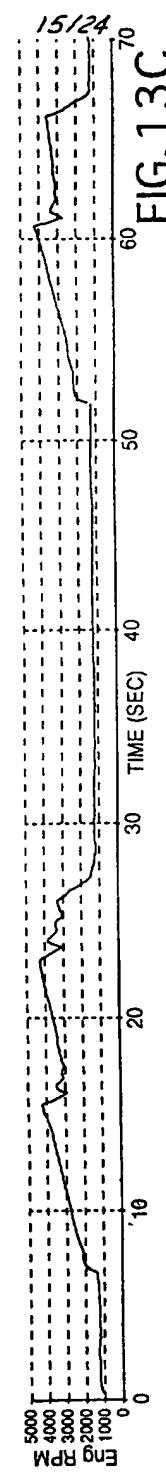
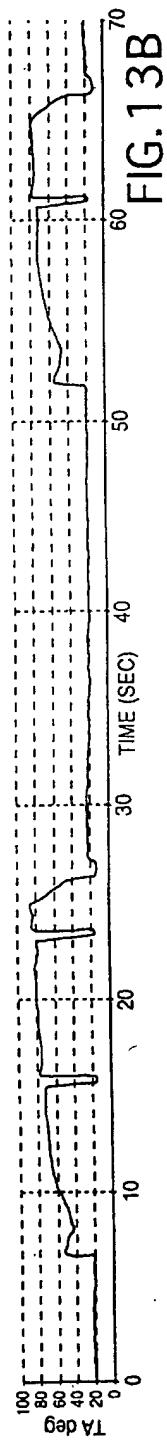
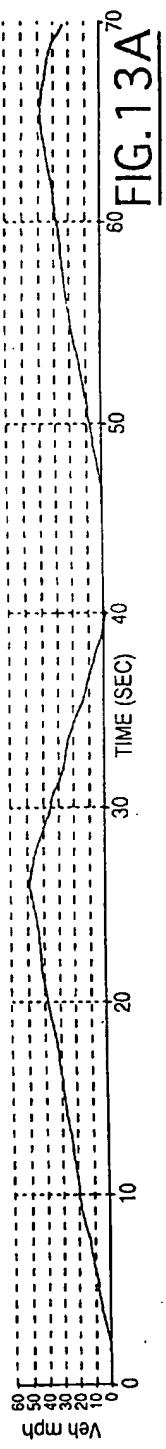


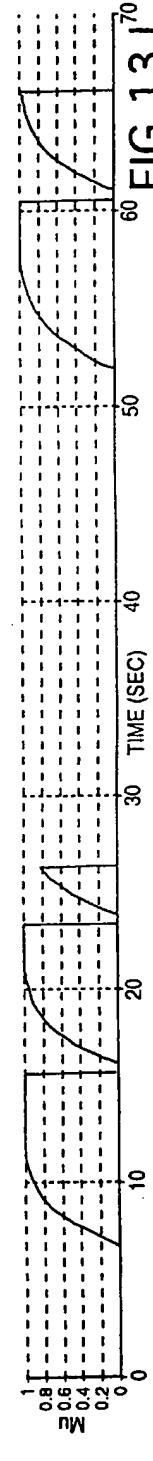
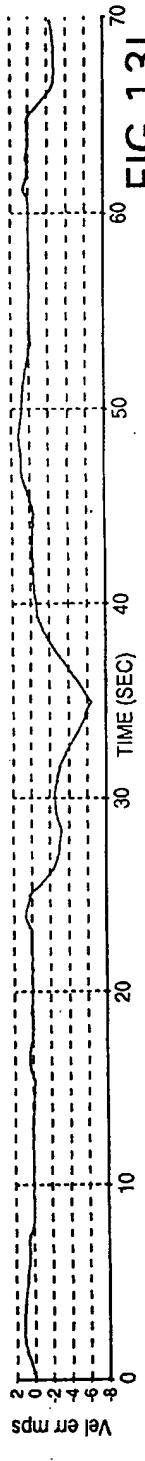
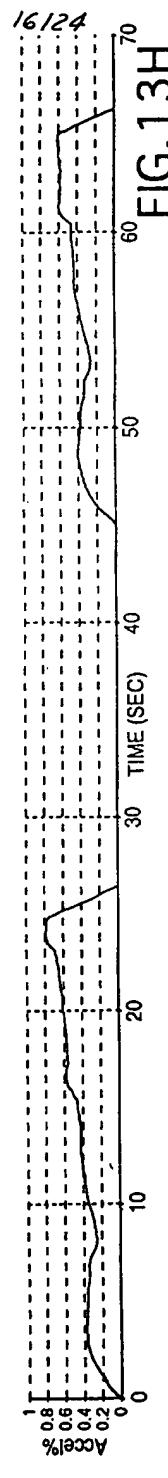
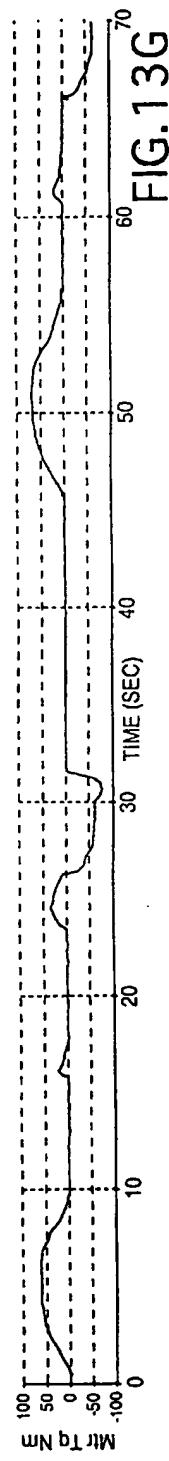
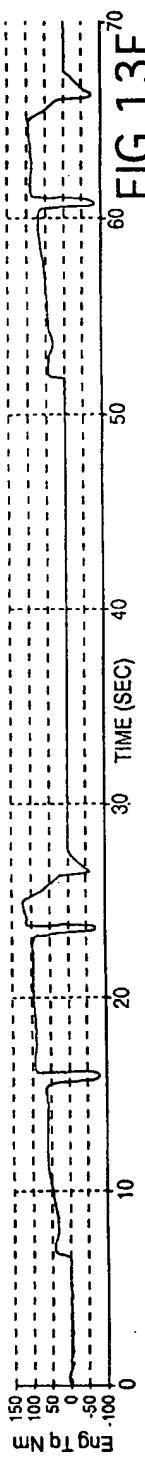
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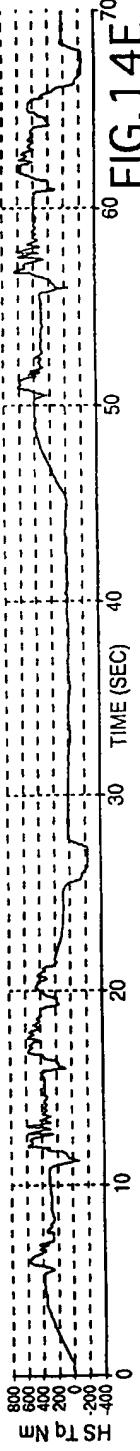
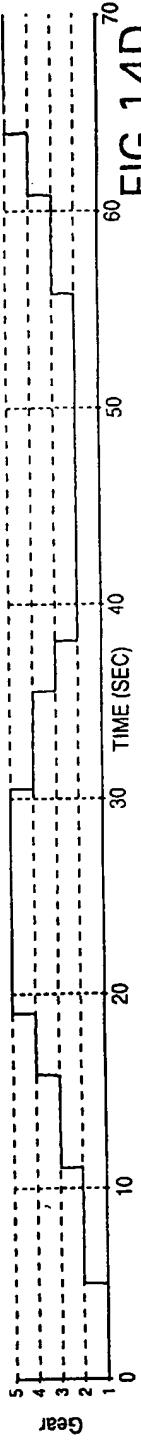
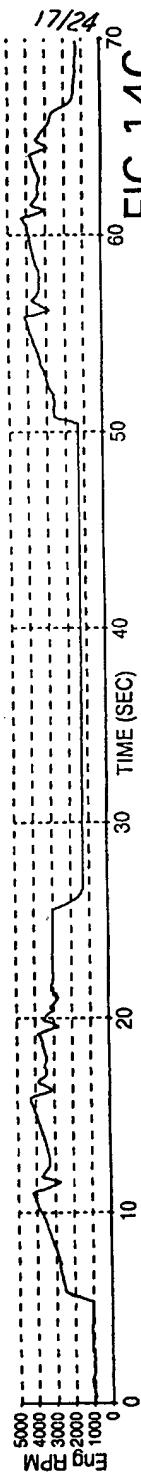
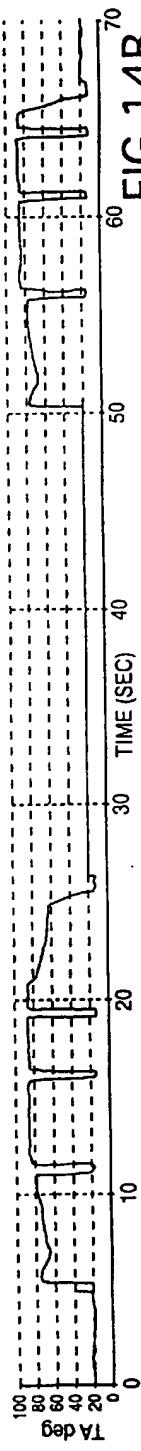
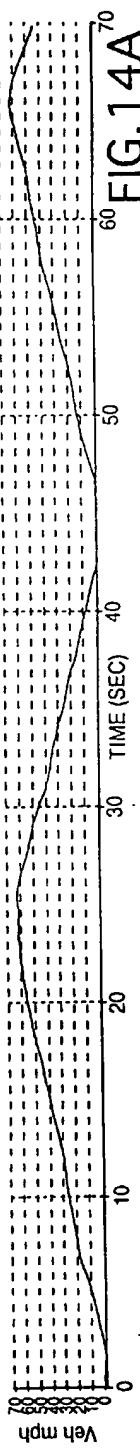




FIG. 14F

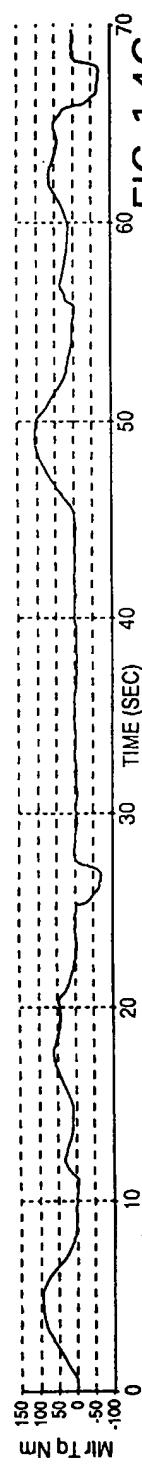


FIG. 14G

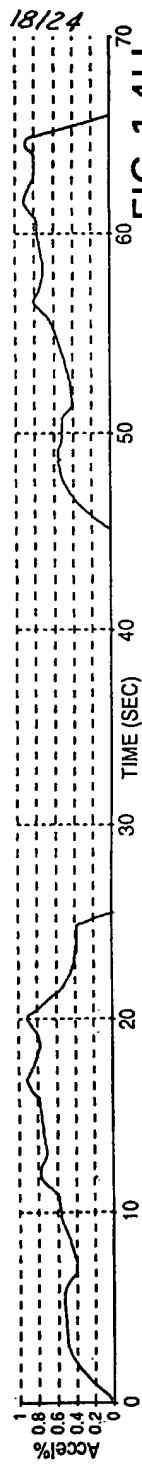


FIG. 14H

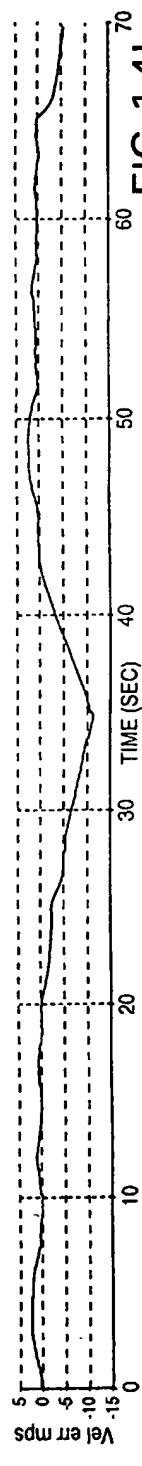


FIG. 14I

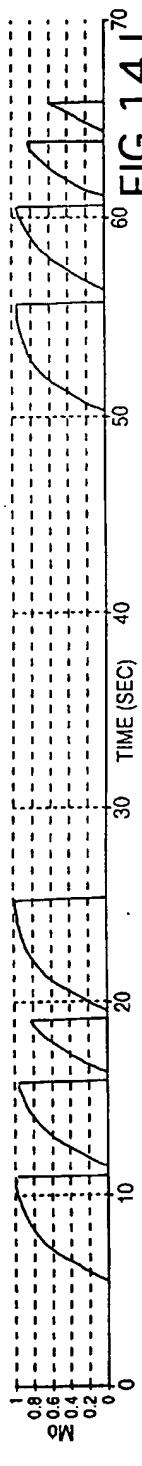
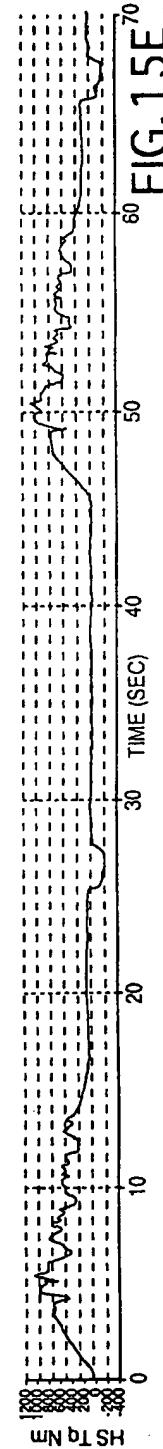
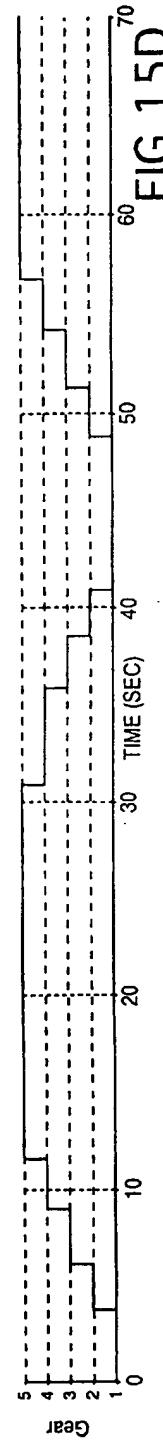
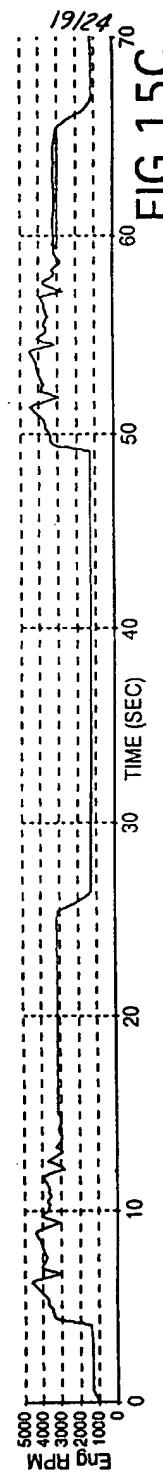
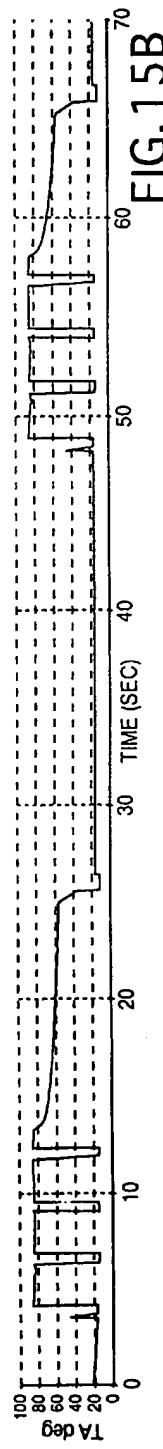
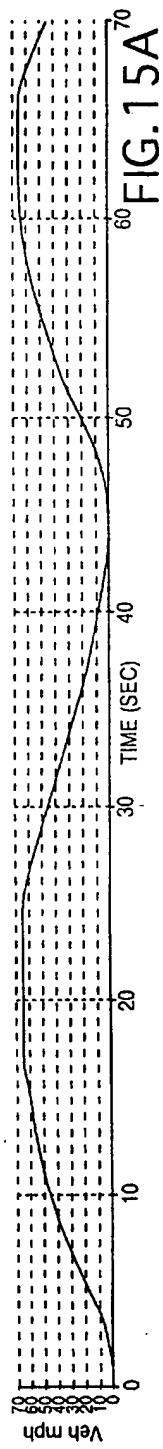
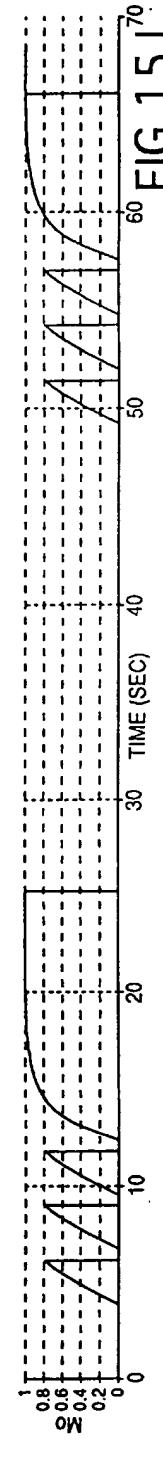
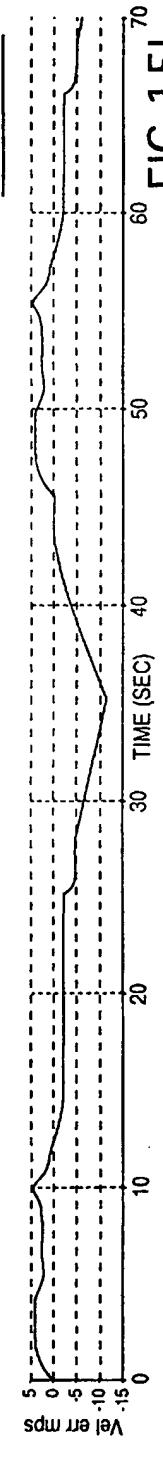
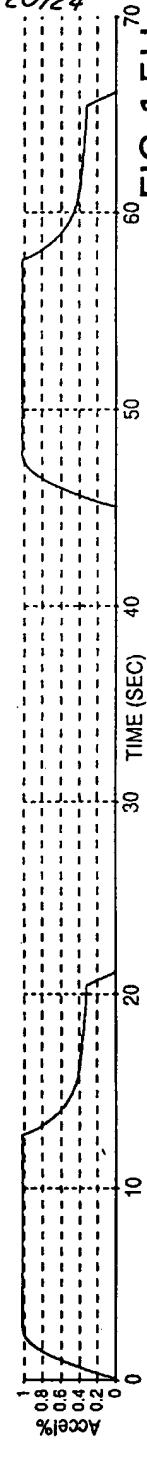
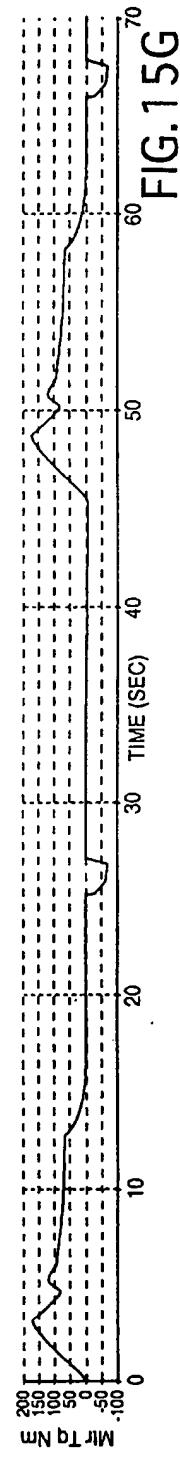
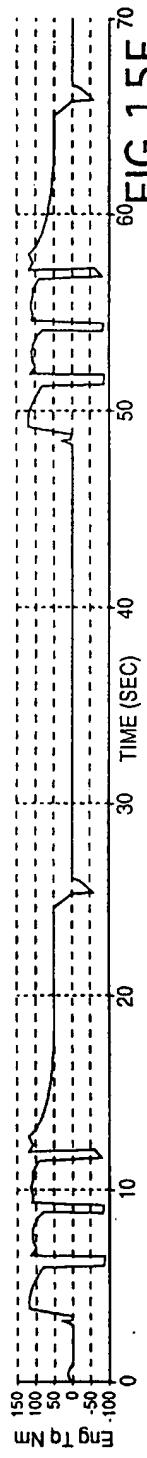


FIG. 14J



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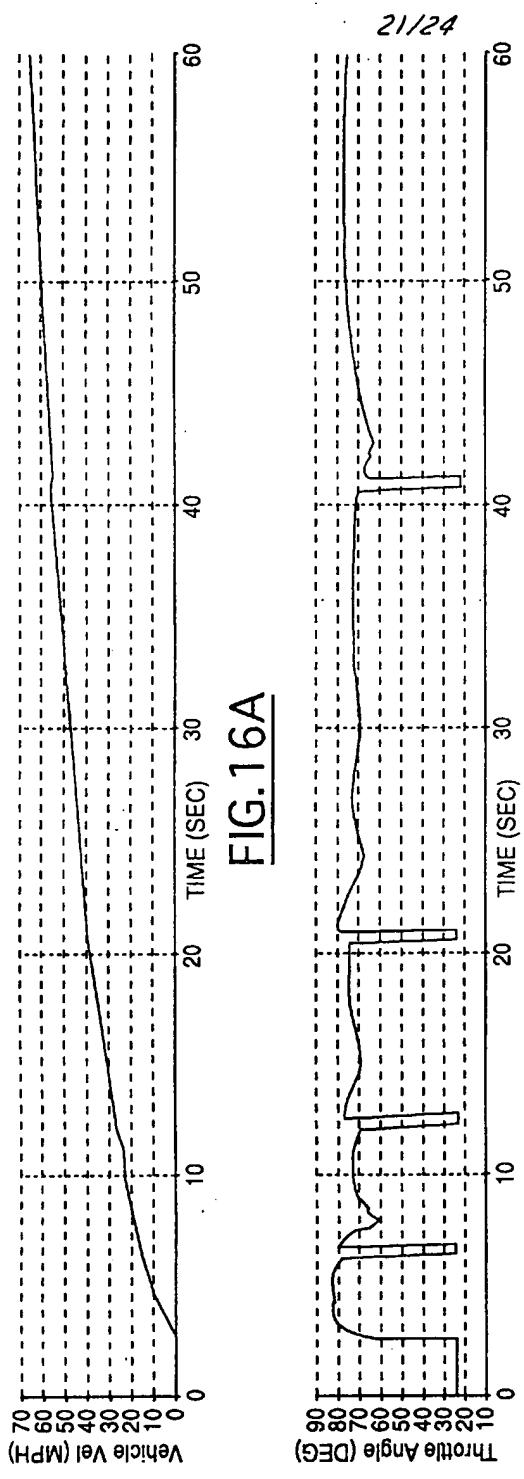


FIG. 16B

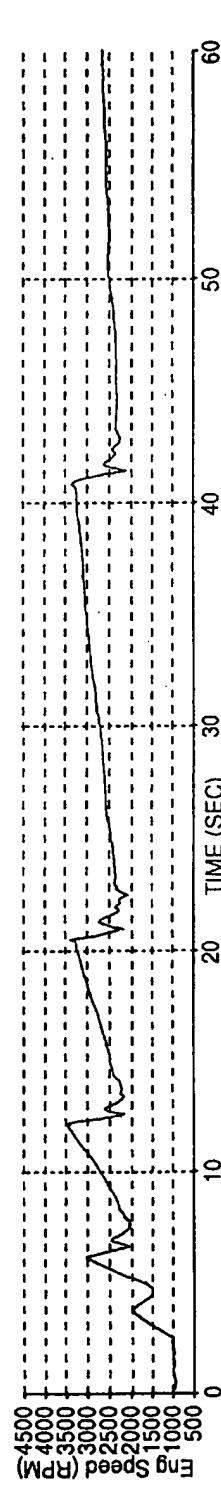


FIG. 16C

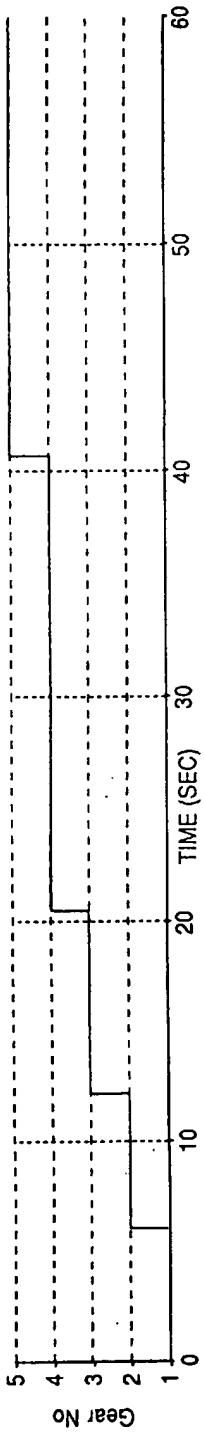


FIG. 16D

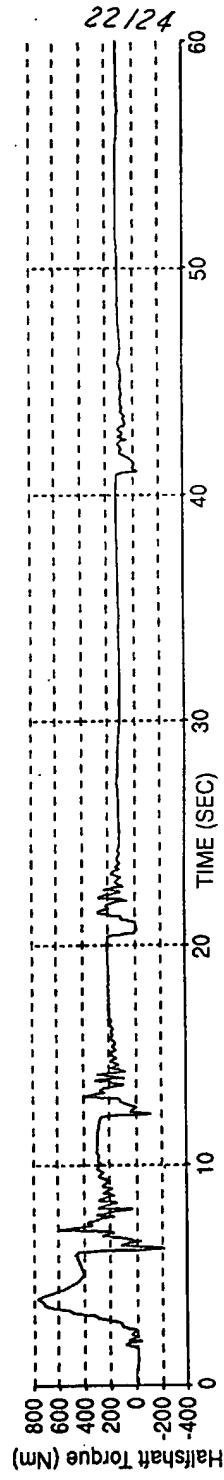


FIG. 16E

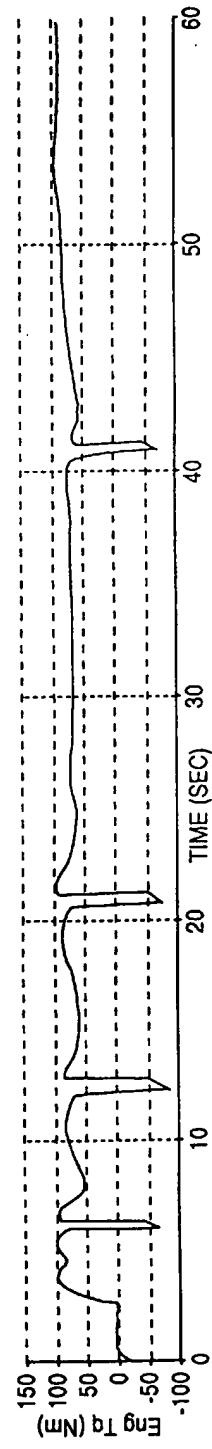
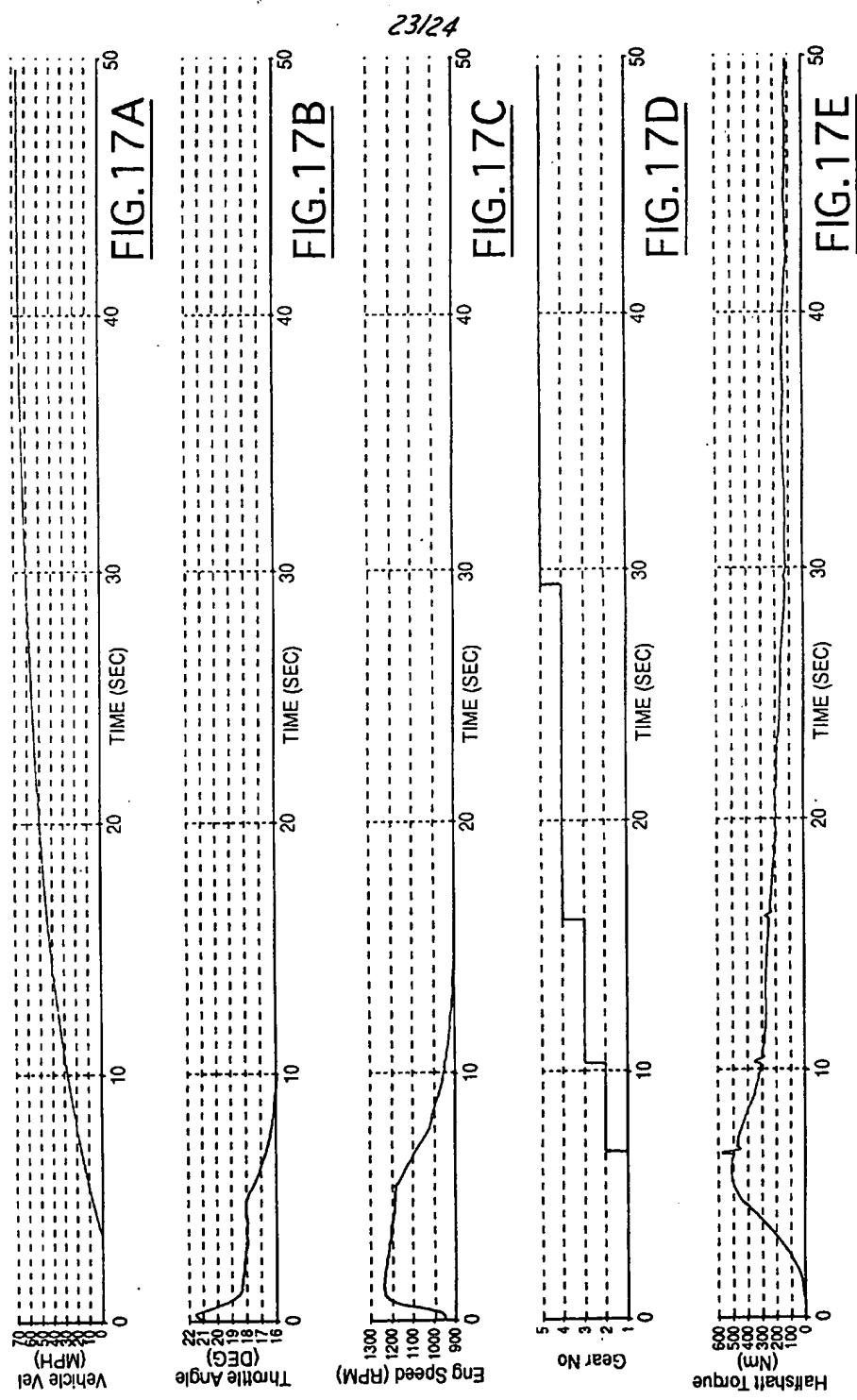


FIG. 16F



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